

ABSTRACT

To provide a leg type mobile robot, in which a downsizing
and wait-saving of floor reaction force detector to be installed
5 on the foot is enabled.

The center P_b of the force sensor is disposed on the
position P_a where the distance to the remotest position of
ground area provided on the bottom of each plate spring part
S1 to S4 is minimum in the standing-still state of the robot
10 R, and the distance L_1 , L_2 , L_3 , and L_4 to the remotest point
of the ground area of each plate spring part S1, S2, S3, and
S4 is equal. The center P_c of the ankle joint is offset in a
rearward direction with respect to the position P_a in a plane
view.

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